Example 5:
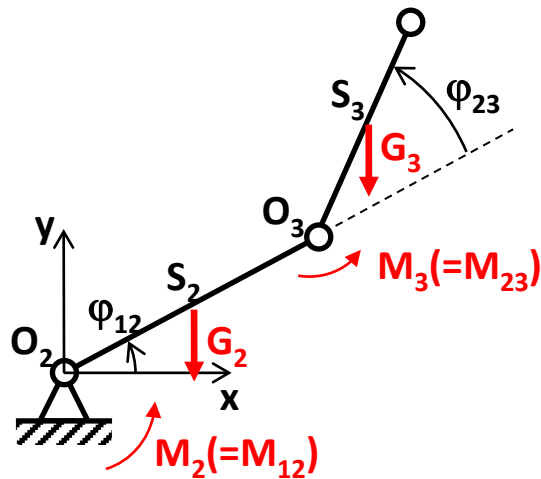
Prepare dynamic control model of the two link manipulator using Matlab – Simulink environment.

Known parameters:
m_2, m_3, I_{2S2}, I_{3S3},
$|O_2S_2|=l_2$,
$|O_3S_3|=l_3$,
$\varphi_{12}(t)$, $\varphi_{23}(t)$,
I_{mot}, k, b (stiffness and damping ratio of the gearbox)